

IN THE SPECIFICATION:

Please amend paragraph 12 on page 5 as follows.

B1 --Figures 1A and 1 B comprise a pair of images taken of a scene ~~the~~ that includes a can and stapler, and will be used to demonstrate the present invention;--

Please amend paragraph 25 on page 8 as follows.

B2 --Matching points in one image 1A with points in another image 1B where both images are taken of a single scene, called the correspondence problem, remains one of the bottlenecks in computer vision and is important to continued development in this field. As is more fully described in the related application entitled "Fast Epipolar Adjustment of Stereo Pairs" (identified above), an adjustment algorithm can be used to adjust the points in the right image 1B in order to more easily correspond to the points in the left image 1A, so that the points in the right image 1B are located along the same line as in the left image 1A, thereby creating images with the desired epipolar geometry. For simplicity, we shall assume that the images ~~1A, ab~~ 1A, 1B already have the desired geometry or that the adjustment algorithm has already been run on the images.--

Please amend paragraph 42 on page 15 as follows.

B3 --Referring now to Figure 6a, a combined disparity map created using the first embodiment of the present invention is shown. This map 6A was generated by combining Figures 4A, 4B and 4C without further modification. The results of applying the additional error elimination steps on the disparity map 6A, i.e., replacing erroneous

entries with a the first true value to the right of that point, are shown in Fig. 6B. As

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Figure 6B demonstrates, the additional error filtering steps help create a vastly superior image resulting in an extremely accurate depiction of the can and stapler scene. The small remaining errors in Figure 6B can be eliminated by applying well-known filtering or feature analysis algorithms.--

Please amend paragraph 43 on page 16 as follows:

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--Referring now to Figure 7A, a combined disparity map (600) generated using the second embodiment of the invention is shown. This map (600) was generated by combining Figures 5A, 5B, and 5C without further modification. The results of applying the additional error elimination steps on the disparity map 7A, i.e., replacing erroneous entries with the first true value to the right of that point, is shown in Fig. 7B. As Figure 7B further demonstrates, the additional steps help create a vastly superior image resulting in an extremely accurate depiction of the can and stapler scene. Additionally, despite the greater number of error points in Figure 7A, the final result looks better than in Fig. 6B because false targets were detected more precisely during the correspondence search.--
